

[Robótica] Canal de Juan Carlos Martín Castillo

- [Canal Juan Carlos Martín Castillo](#)
- [RAPID avanzado](#)
- [Revista de Electricidad, Electrónica y Automática](#)

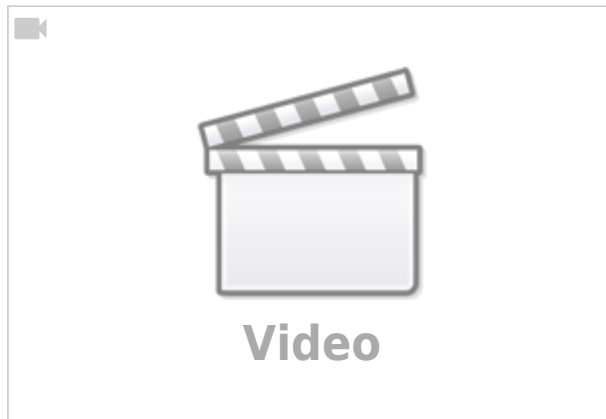
RobotStudio



Videos

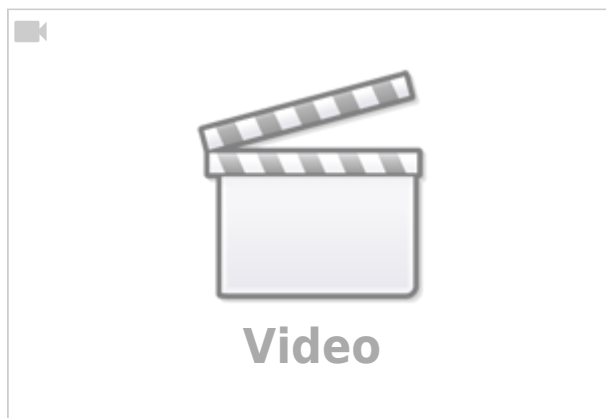
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[Sistemas de coordenadas \(51m 17s\)](#)



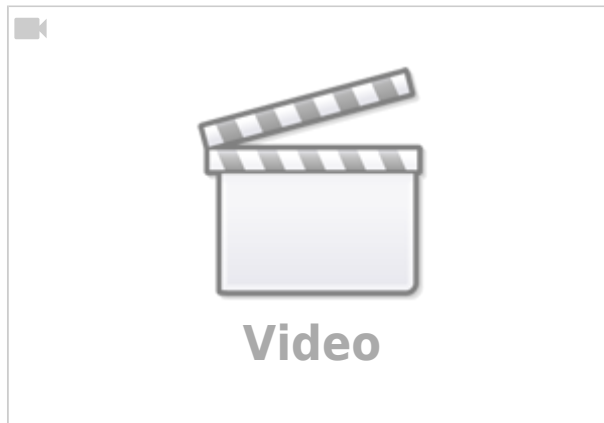
2

[Diferentes formas de crear estaciones \(19m 22s\)](#)



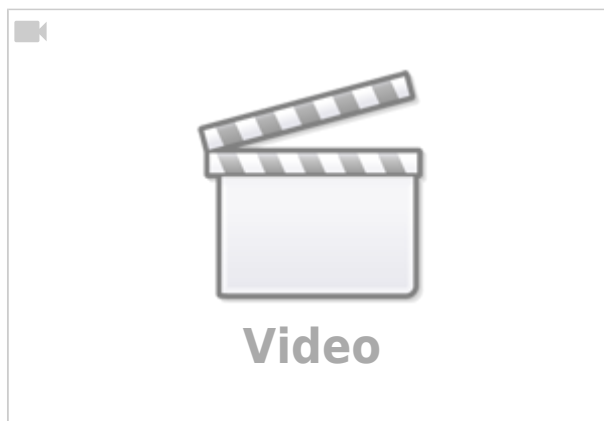
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[Configuración de una estación \(24m 51s\)](#)



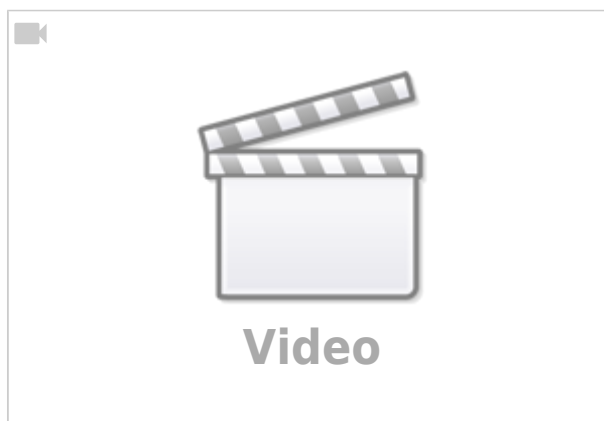
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[Configuración de una controladora virtual \(11m 12s\)](#)



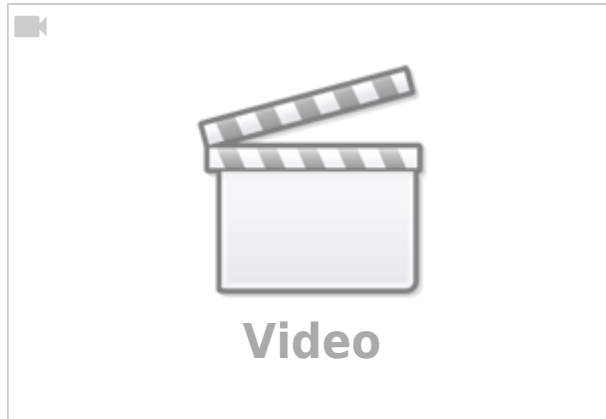
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[Modelado \(9m 25s\)](#)



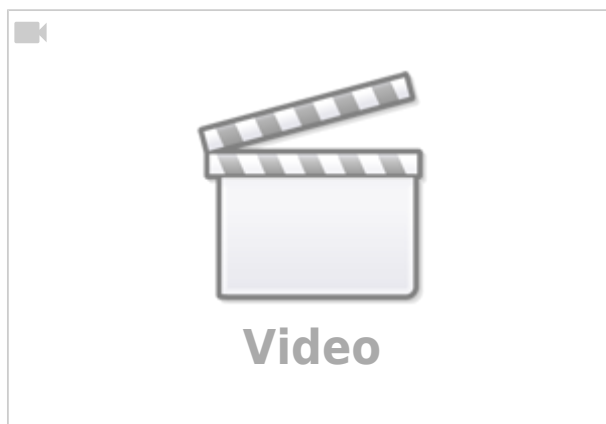
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[Uso de las herramientas de modelado \(I\) \(33m 24s\)](#)



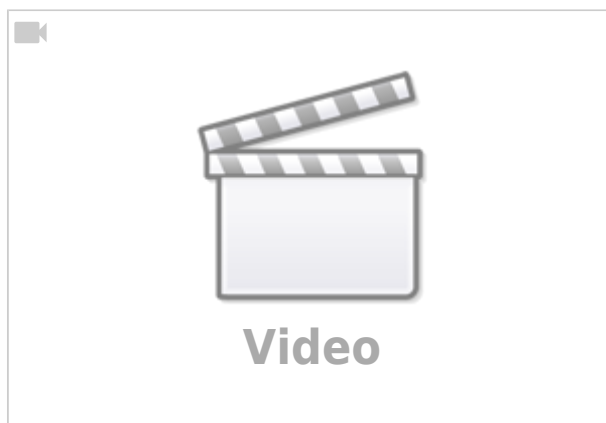
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[Configuración básica de la herramienta \(25m 11s\)](#)



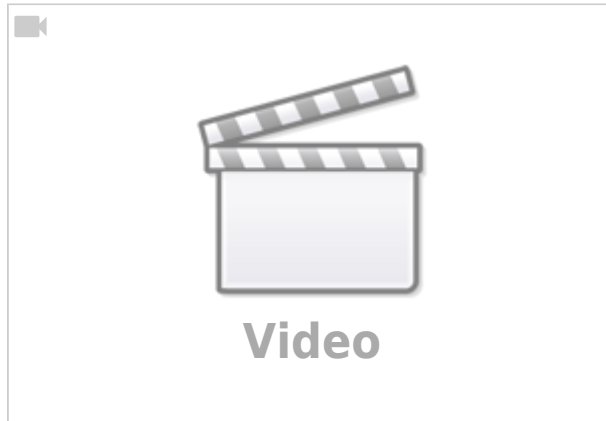
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[Configuración avanzada de herramientas \(35m 56s\)](#)



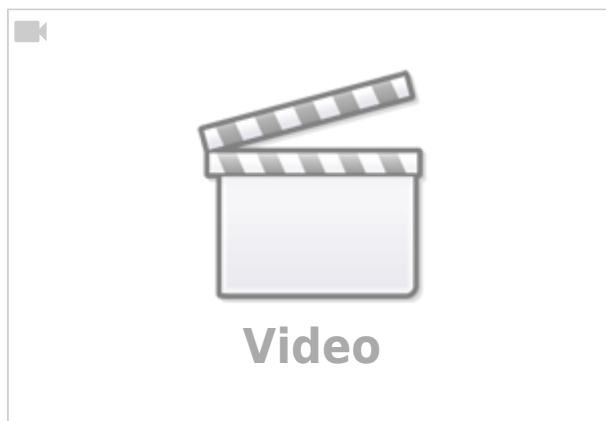
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[Programación básica de posiciones y trayectorias \(23m 20s\)](#)



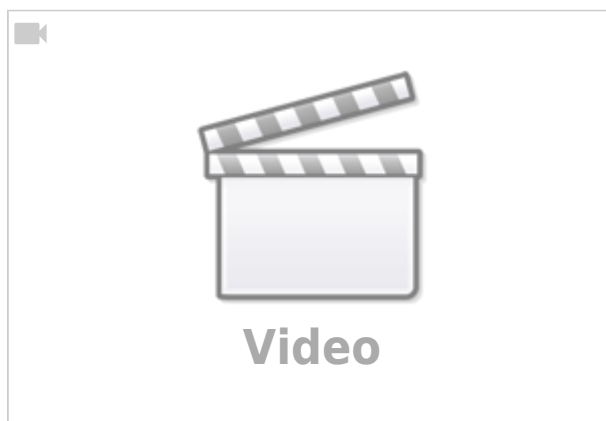
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[Iniciación al uso de los WorkObjects \(12m 22s\)](#)



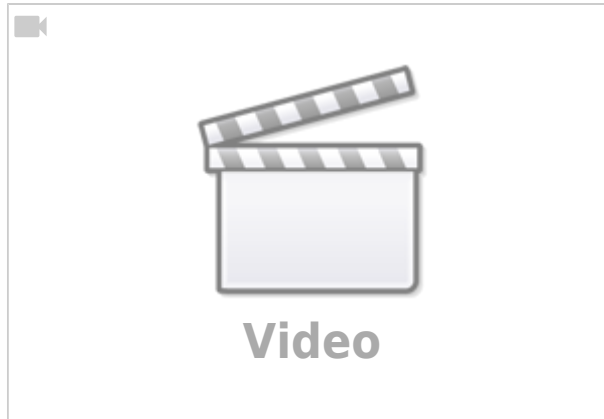
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[Aplicación práctica de los WorkObjects- Instrucciones de movimiento \(35m 14s\)](#)

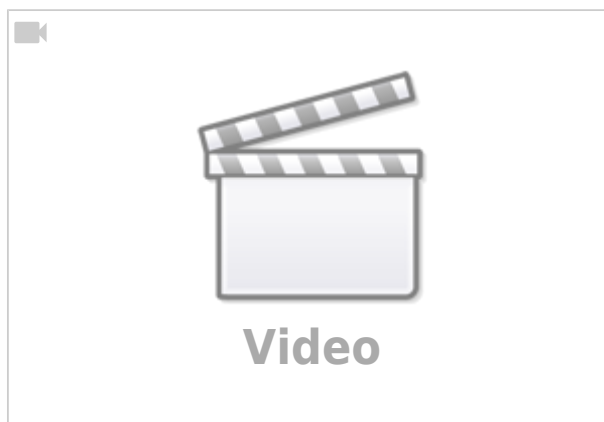


12

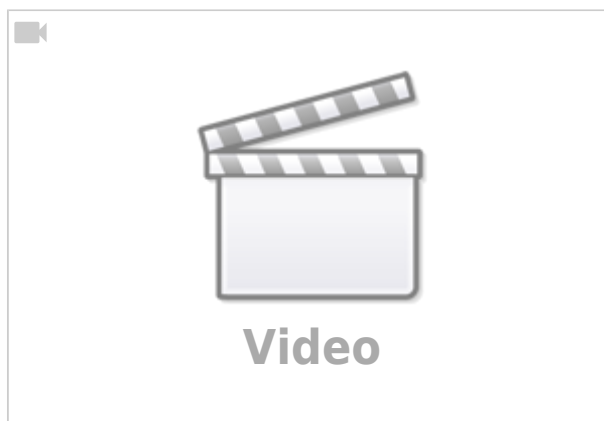
[Simulación en RobotStudio 6 \(6m 37s\)](#)



13

[Iniciación a la programación en RAPID \(34m 55s\)](#)

14

[Saltos, variables y condicionales \(16m 53s\)](#)

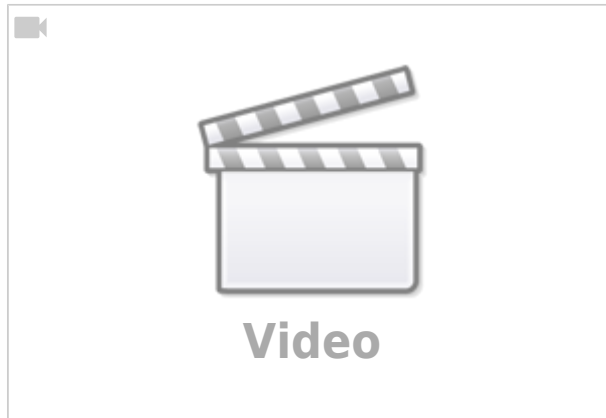
FlexPendant



Vídeos

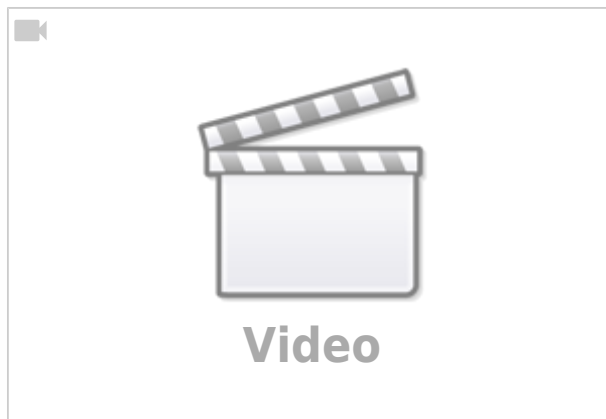
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[Introducción al sistema robótico IRB 120 \(18m 01s\)](#)



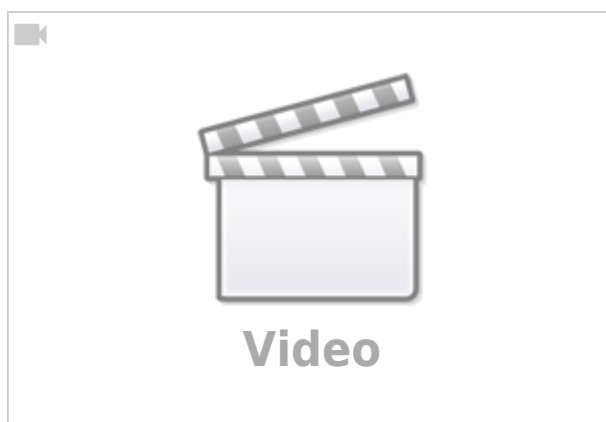
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[Uso del FlexPendant \(22m 58s\)](#)



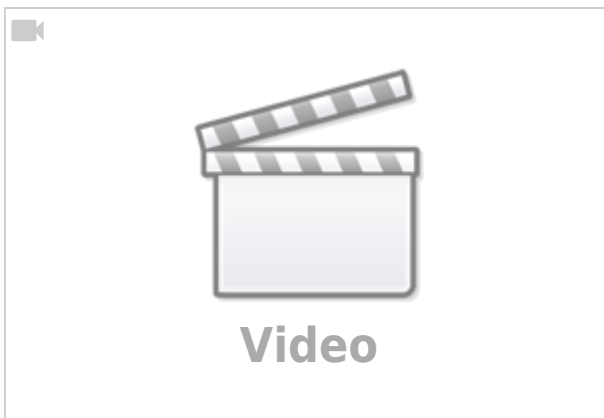
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[Programación de trayectorias con FlexPendant \(13m 32s\)](#)

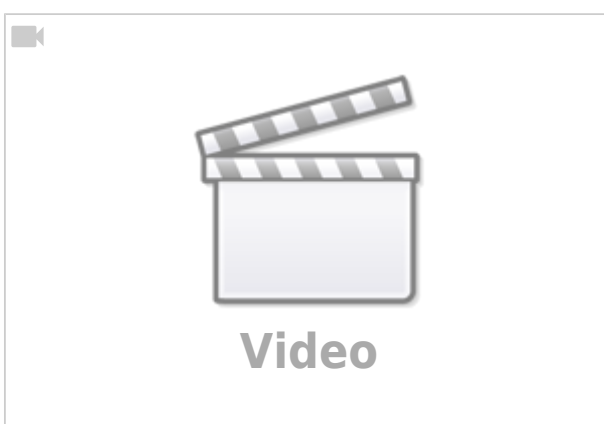


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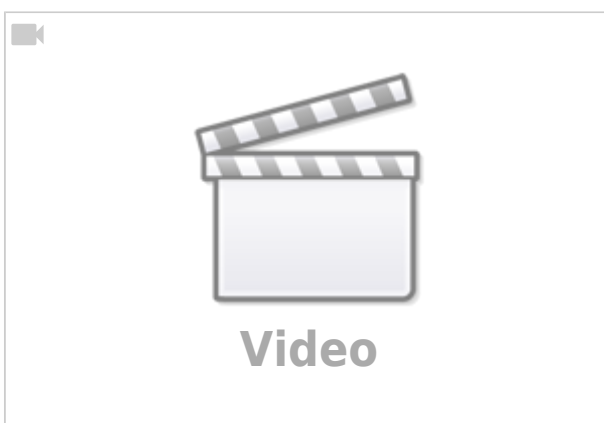
[Instrucciones MoveJ, MoveL y MoveC \(16m 04s\)](#)



5

[Programación y configuración con FlexPendant \(I\) \(31m 11s\)](#)

6

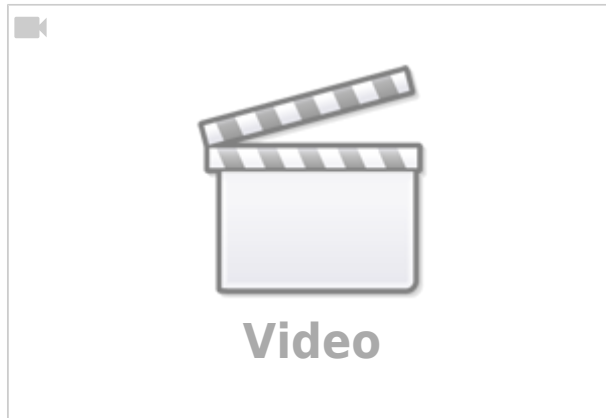
[Programación y configuración con FlexPendant \(II\) \(25m 17s\)](#)

Otros

[Vídeos](#)

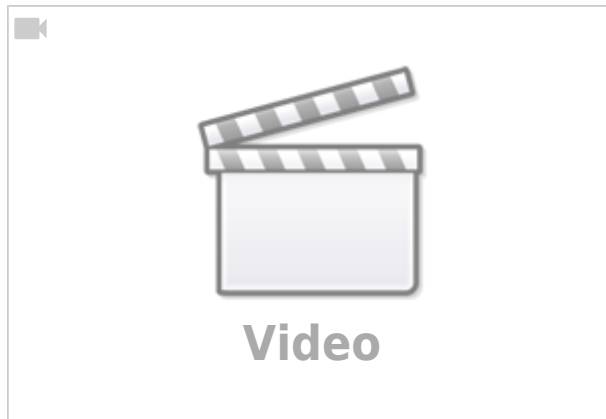
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[Entradas y Salidas \(I\) \(28m 35s\)](#)



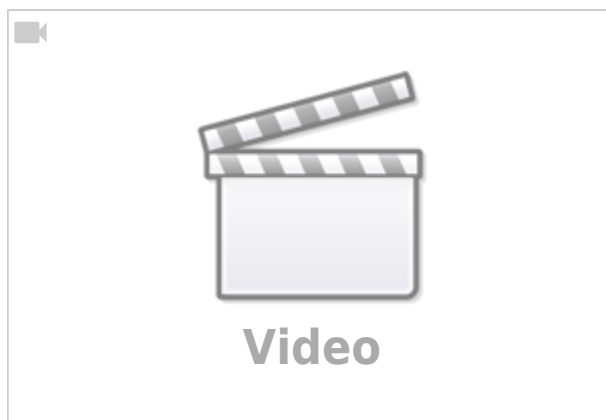
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[Entradas y Salidas \(II\) \(42m 53s\)](#)



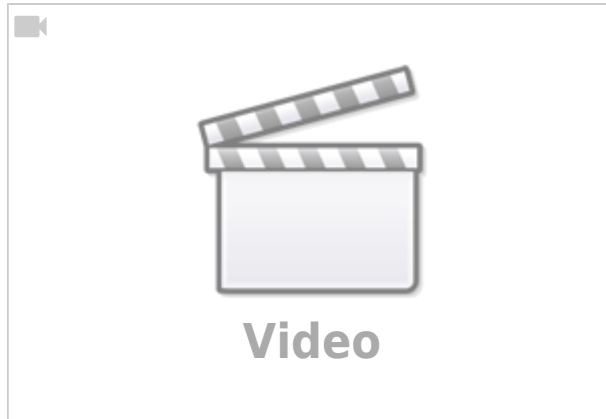
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[Entradas y salidas virtuales en Robotware 6 \(14m 34s\)](#)



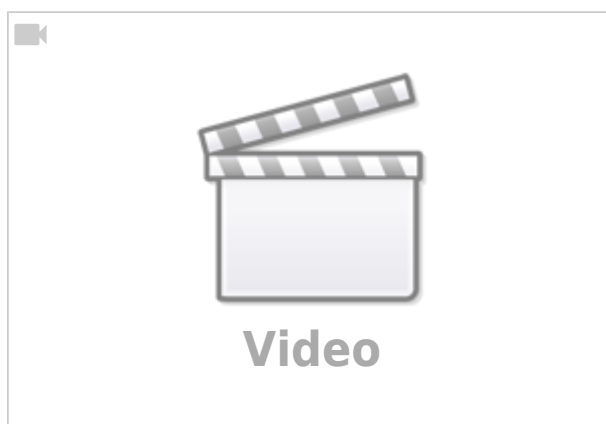
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[Detener o reanudar el movimiento de un robot con entradas digitales \(4m 01s\)](#)



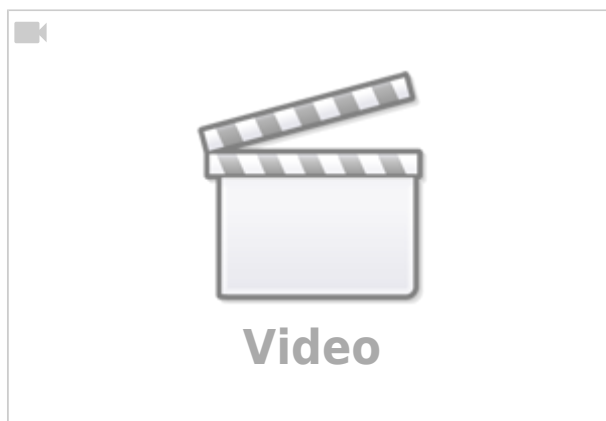
5

Propuesta de actividad: Paletizado (0m 43s)



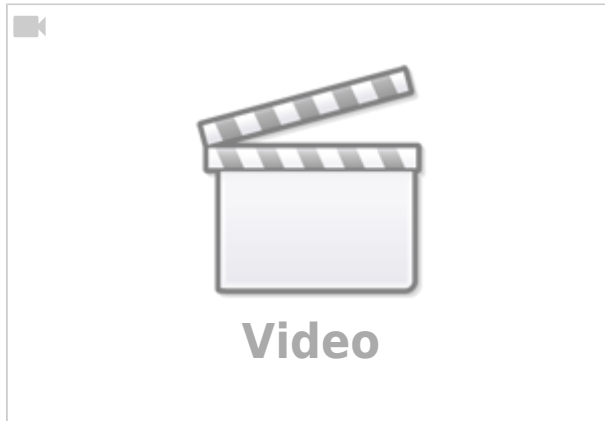
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Iniciación al uso de Smart Components (34m 03s)



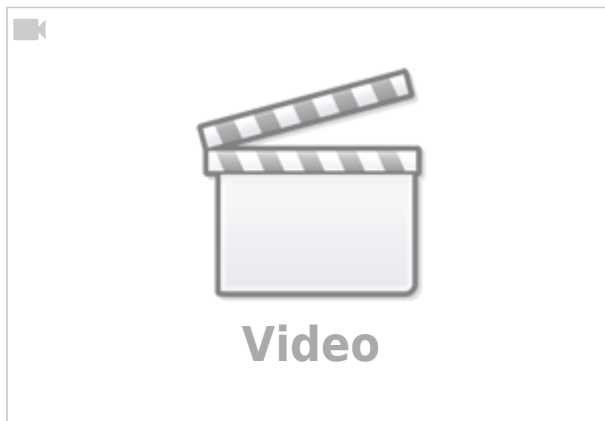
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Kit de Smart Components para RobotStudio (11m 58s)



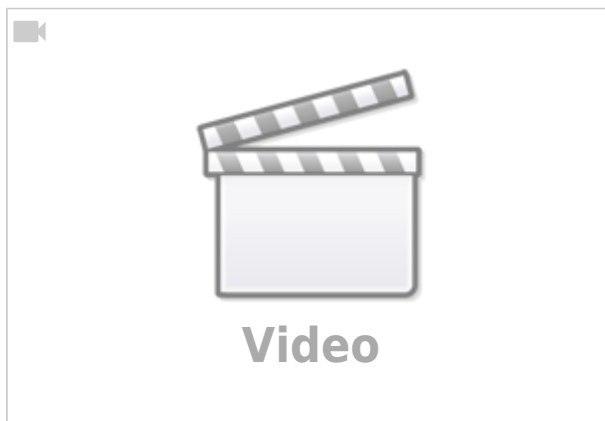
8

[Comunicación con WinCC Flexible mediante OPC Server \(51m 40s\)](#)



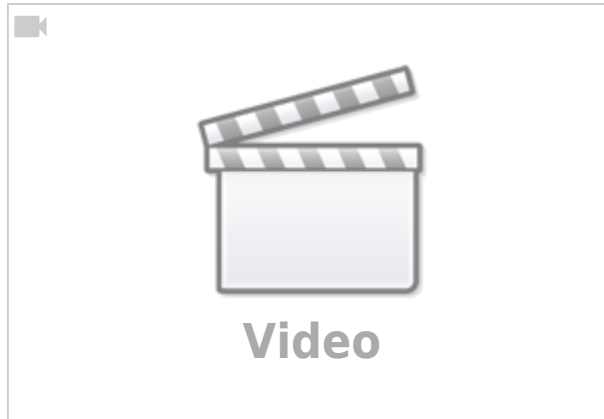
9

[Proyecto \(1\): Programando y copiando trayectorias \(19m 12s\)](#)



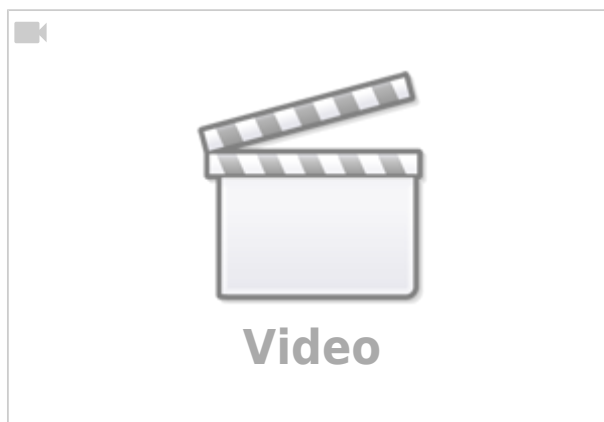
10

[Proyecto \(2\): Uso de If-Then, For, CallByVar, TPreReadNumb \(21m 36s\)](#)



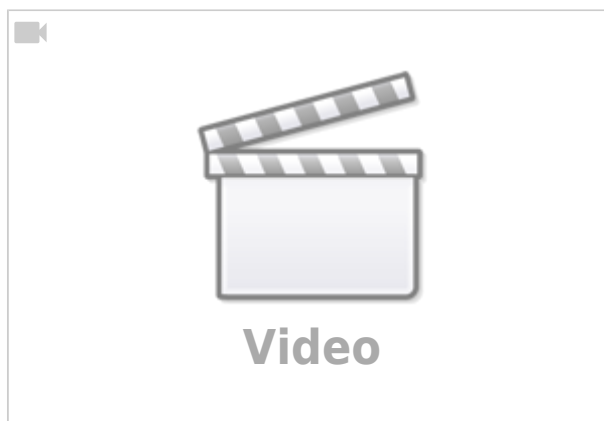
11

Proyecto (3): Activar salidas digitales con SetDO (22m 05s)



12

Proyecto (4): HMI en FlexPendant con ScreenMaker (42m 45s)



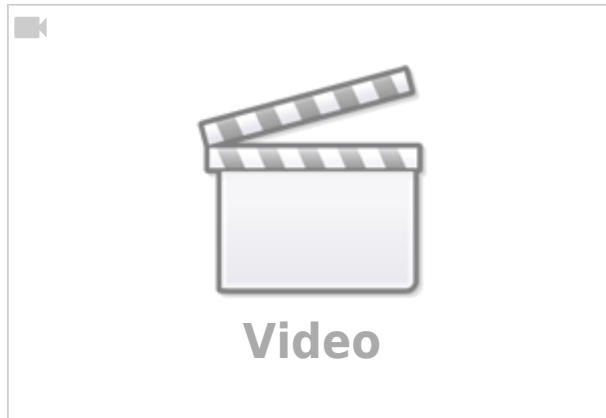
RAPID avanzado



Vídeos

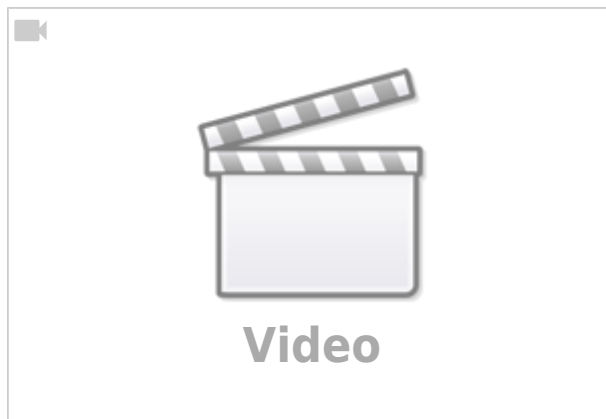
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01 - Tipos de datos y procedimiento con argumentos (21m 48s)



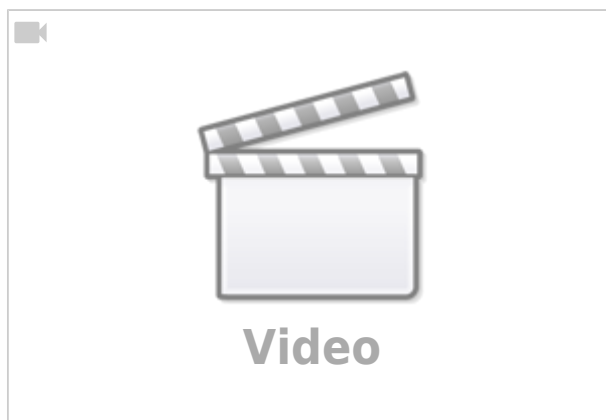
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02 - AliasIO para controlar salidas digitales (7m 47s)



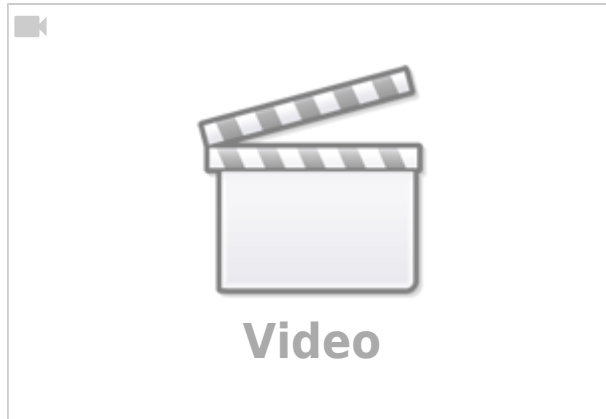
3

03 - Posicionamiento basado en variables (uso del pos.trans y Cpos) (34m 48s)

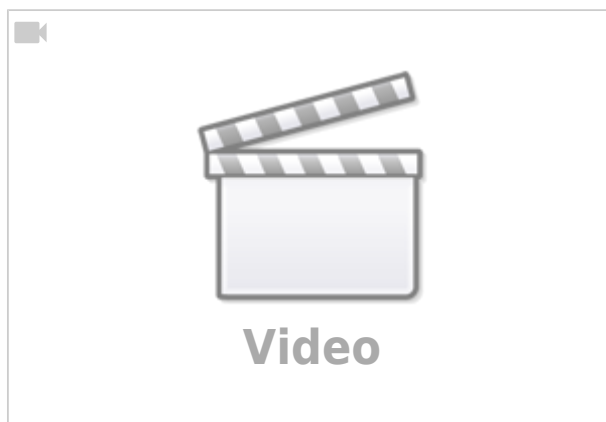


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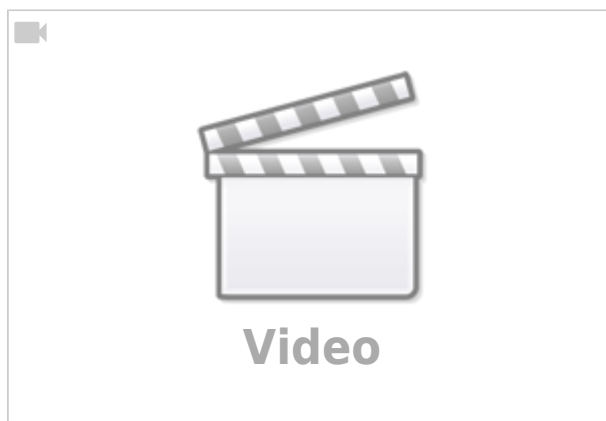
04 - Array de posiciones tipo robtarget (11m 11s)



5

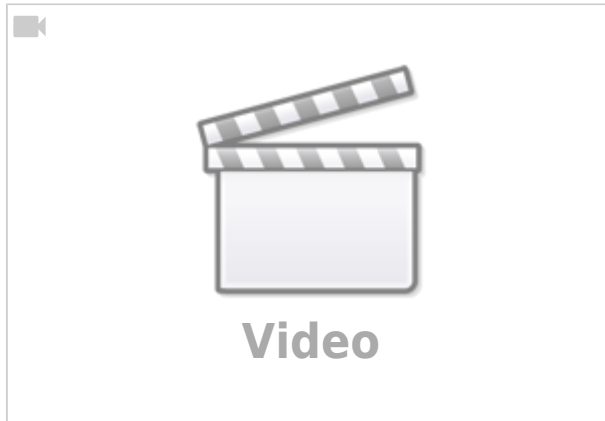
[05 - Paletizado con Offset y bucles FOR \(22m 6s\)](#)

6

[06 - Trayectoria rectangular dinámica \(18m 38s\)](#)

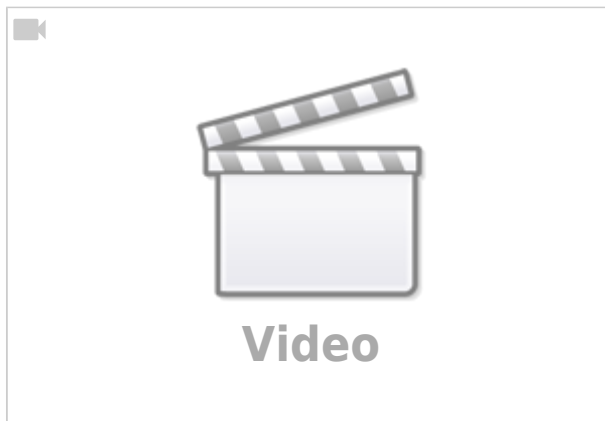
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[07 - Trayectoria triangular dinamica \(11m 22s\)](#)



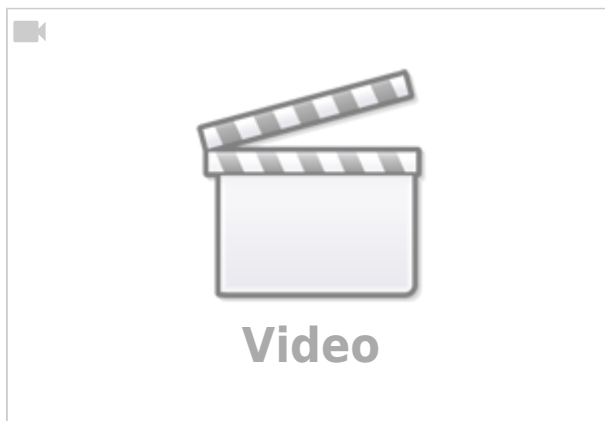
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[08 - Trayectoria circular dinamica \(14m 5s\)](#)



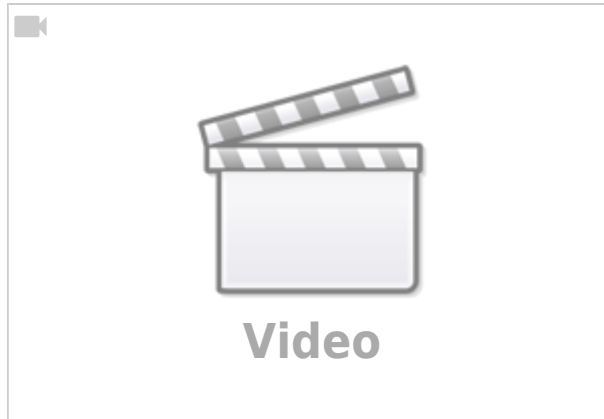
9

[09 - Posicionamiento relativo Offs vs RelTool \(14m 25s\)](#)



10

[10 - Trayectoria circular dinamica con Offs y RelTool \(7m 24s\)](#)



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